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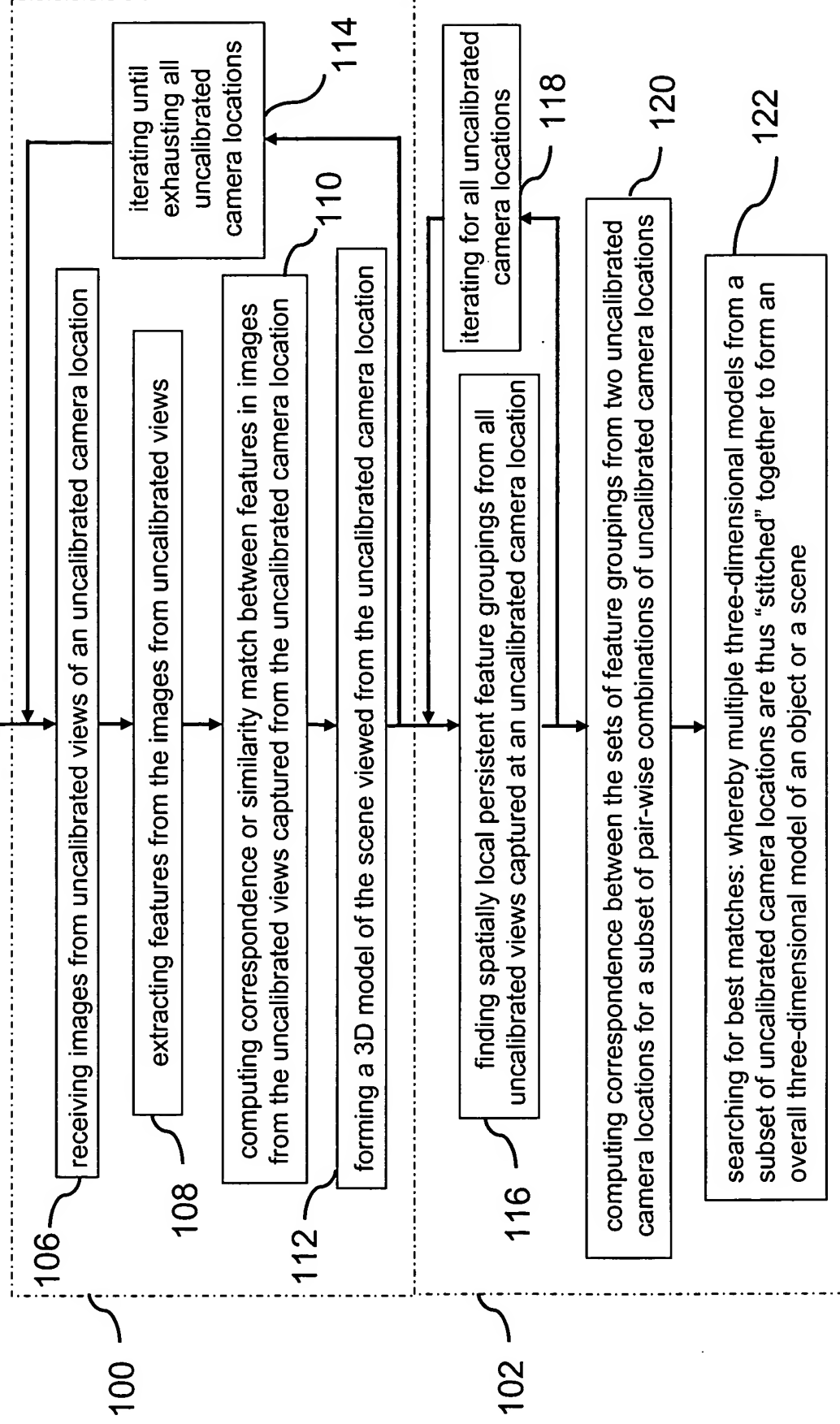


FIG. 1

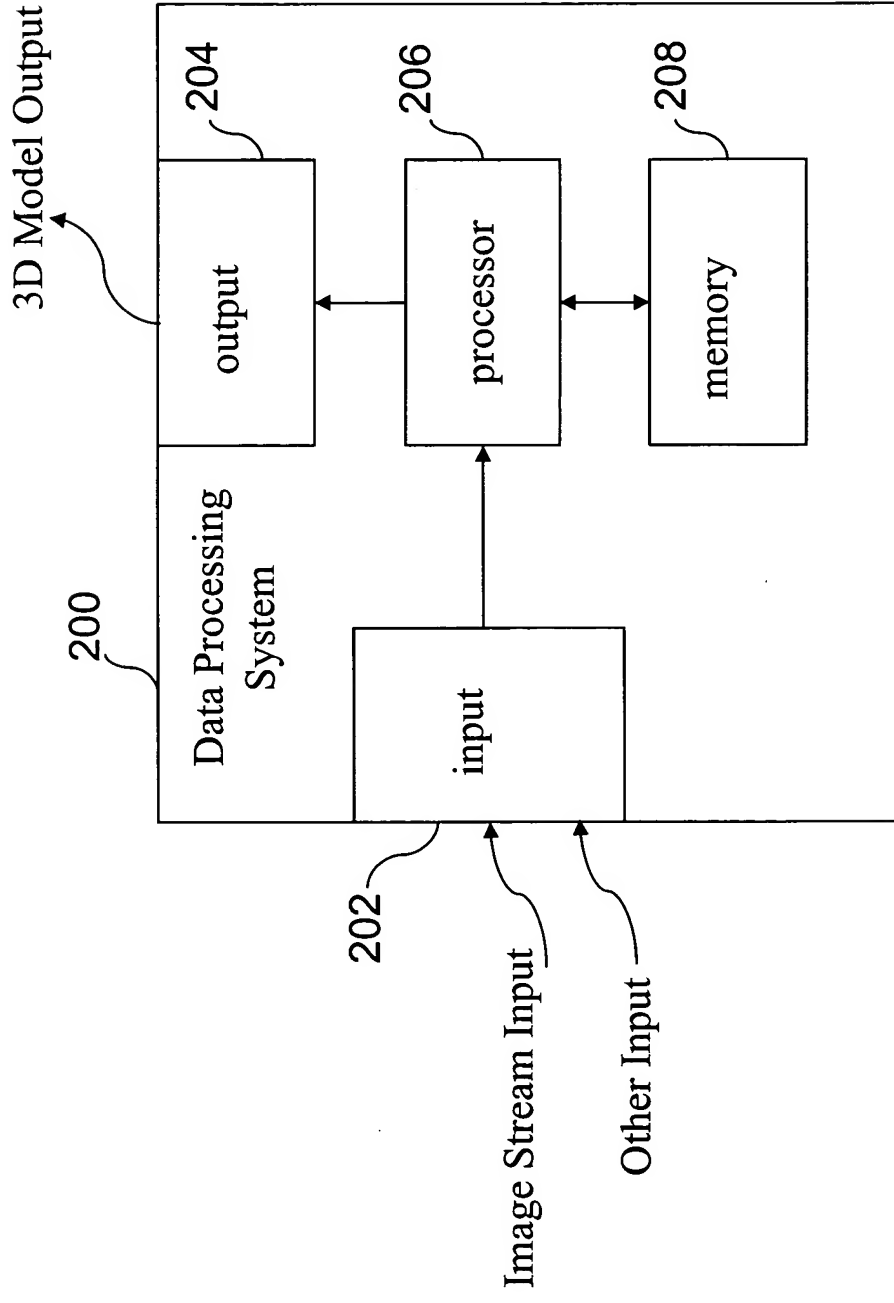


FIG. 2

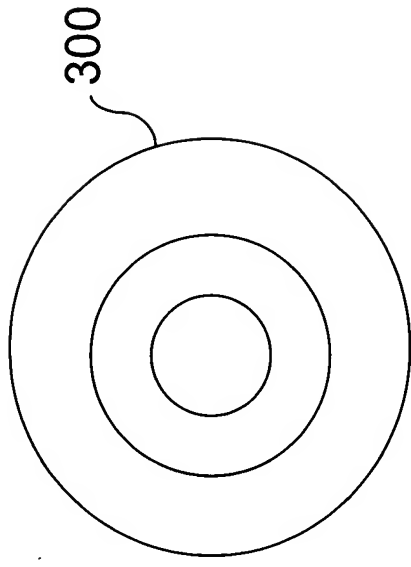
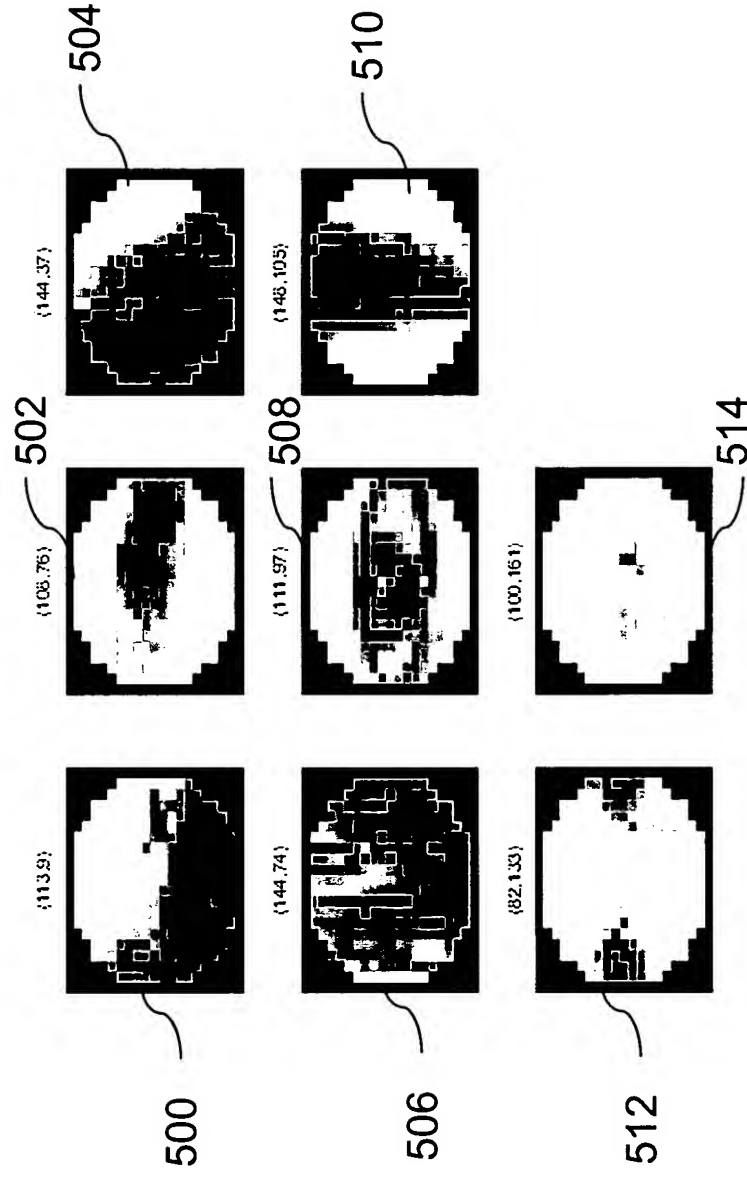


FIG. 3



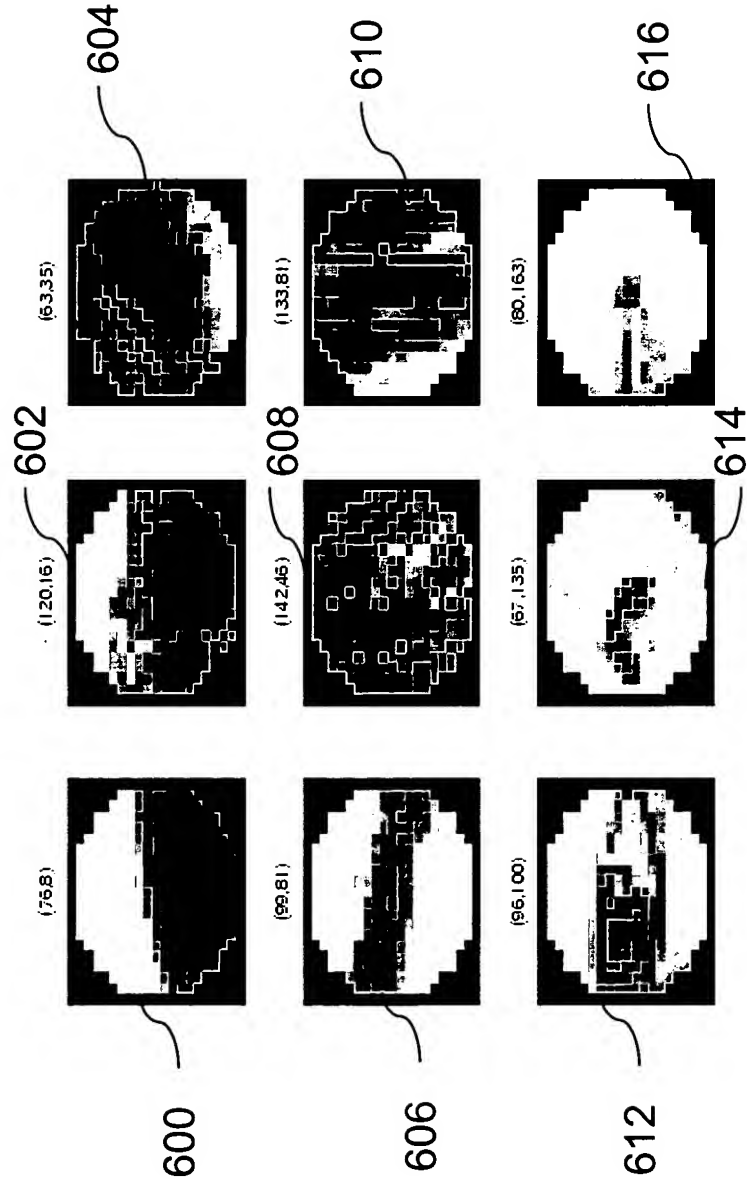
The features identified in the front view image 400 and the side view image 402 which the embodiment seeks to match.

FIG. 4



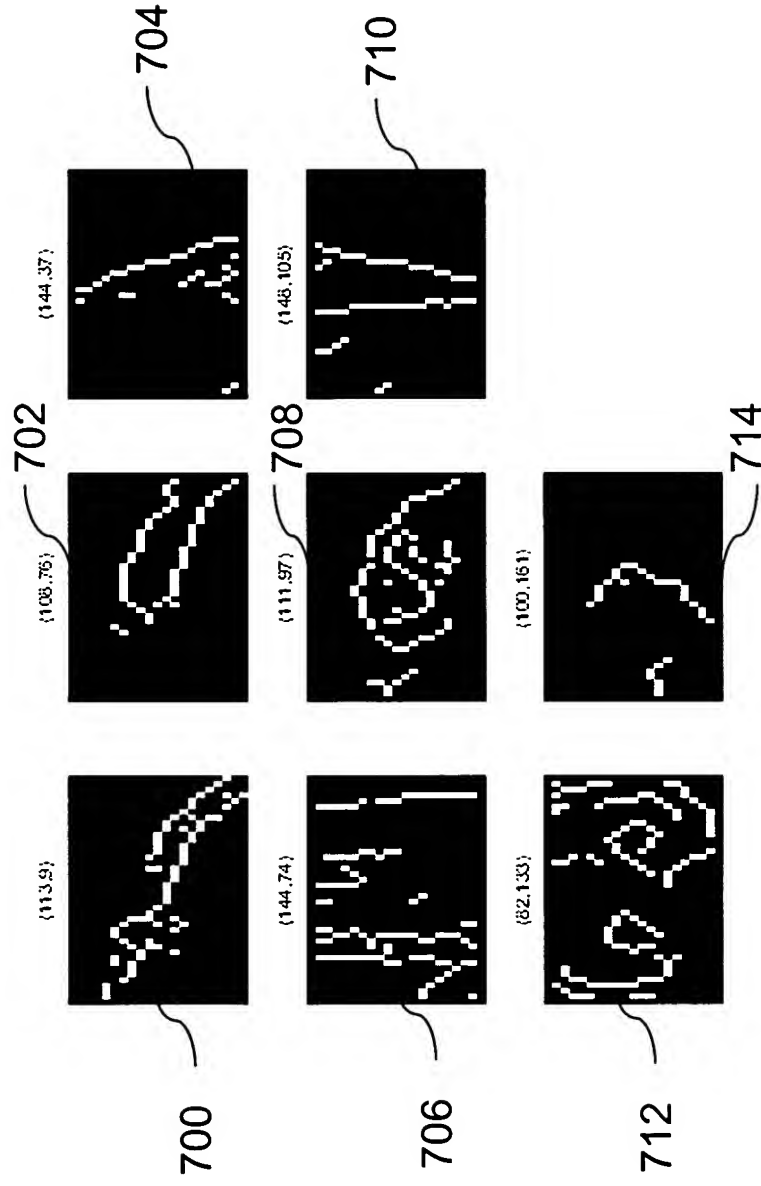
The intensity blocks around the features to be matched in the front view. The small numbers place above each intensity block represent the spatial position of the corresponding feature in the image.

FIG. 5



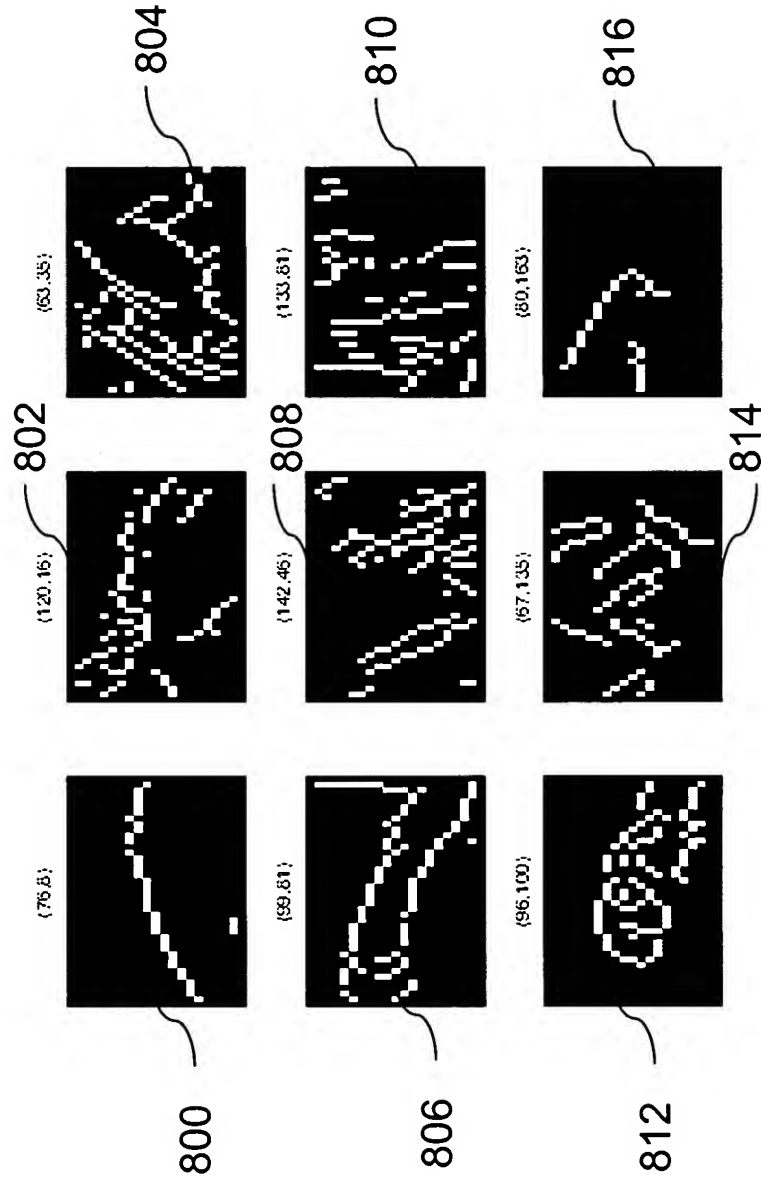
The intensity blocks around the features to be matched in the side view. The small numbers place above each intensity block represent the spatial position of the corresponding feature in the image.

FIG. 6



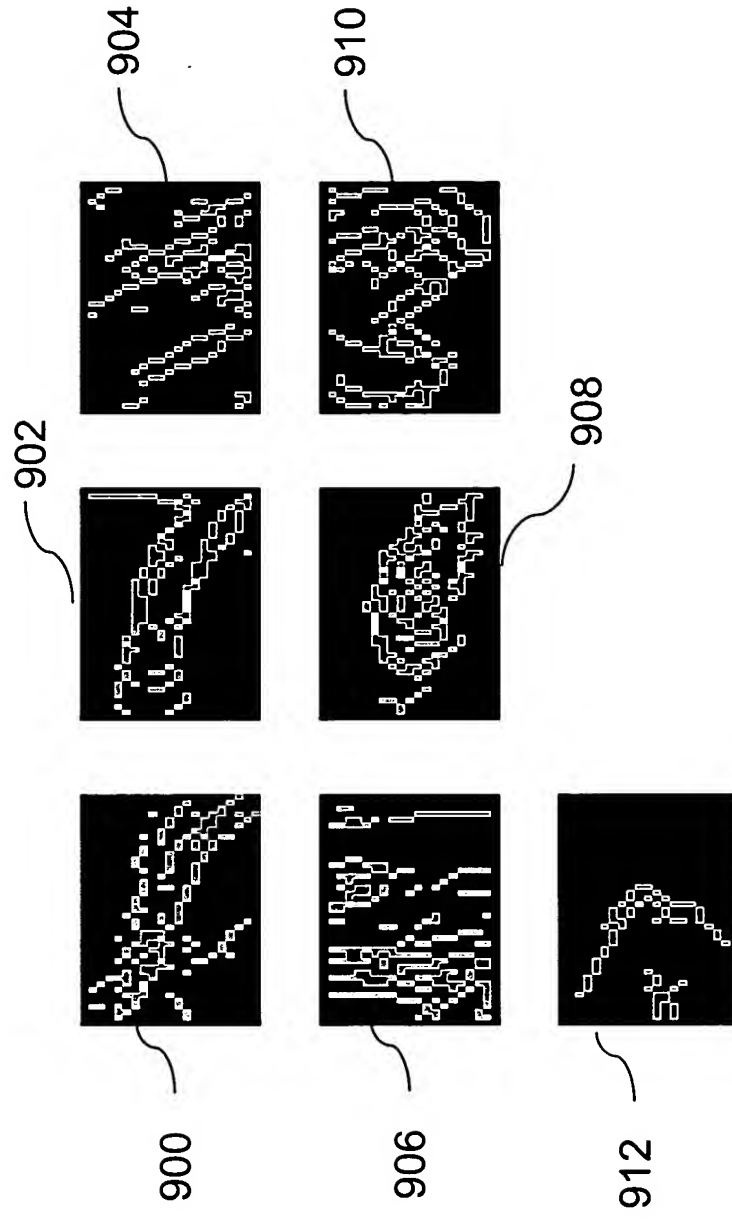
The shape of the significant image attributes in the front view around the previous feature points extracted. The small numbers place above each intensity block represent the spatial position of the corresponding feature in the image.

FIG. 7



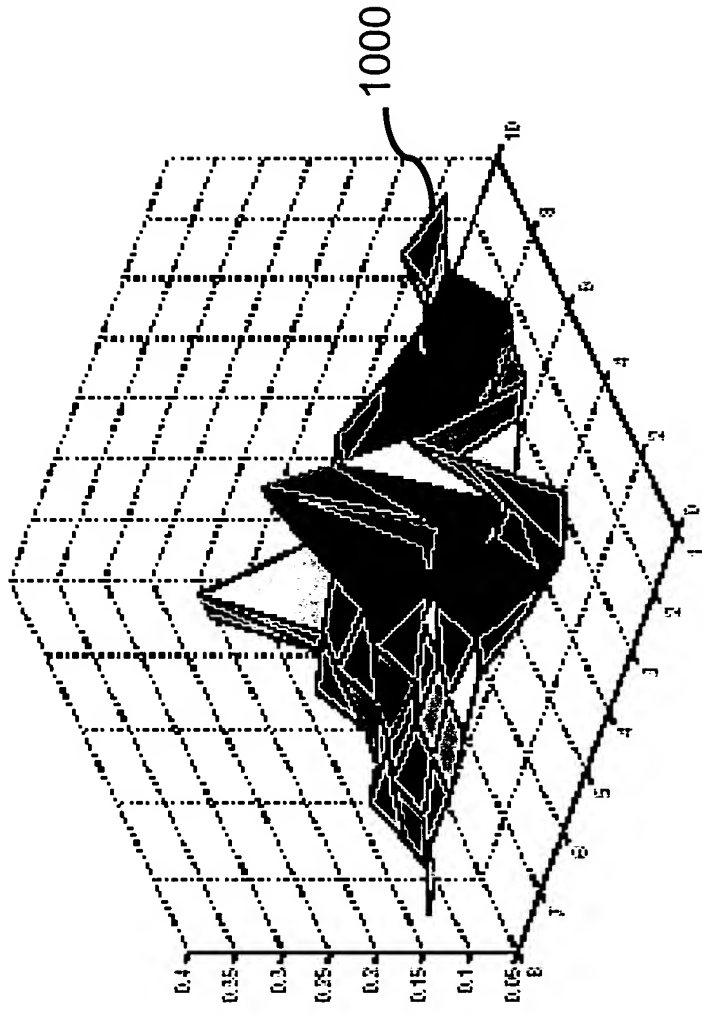
The shape of the significant image attributes in the side view around the previous feature points extracted. The small numbers place above each intensity block represent the spatial position of the corresponding feature in the image.

FIG. 8



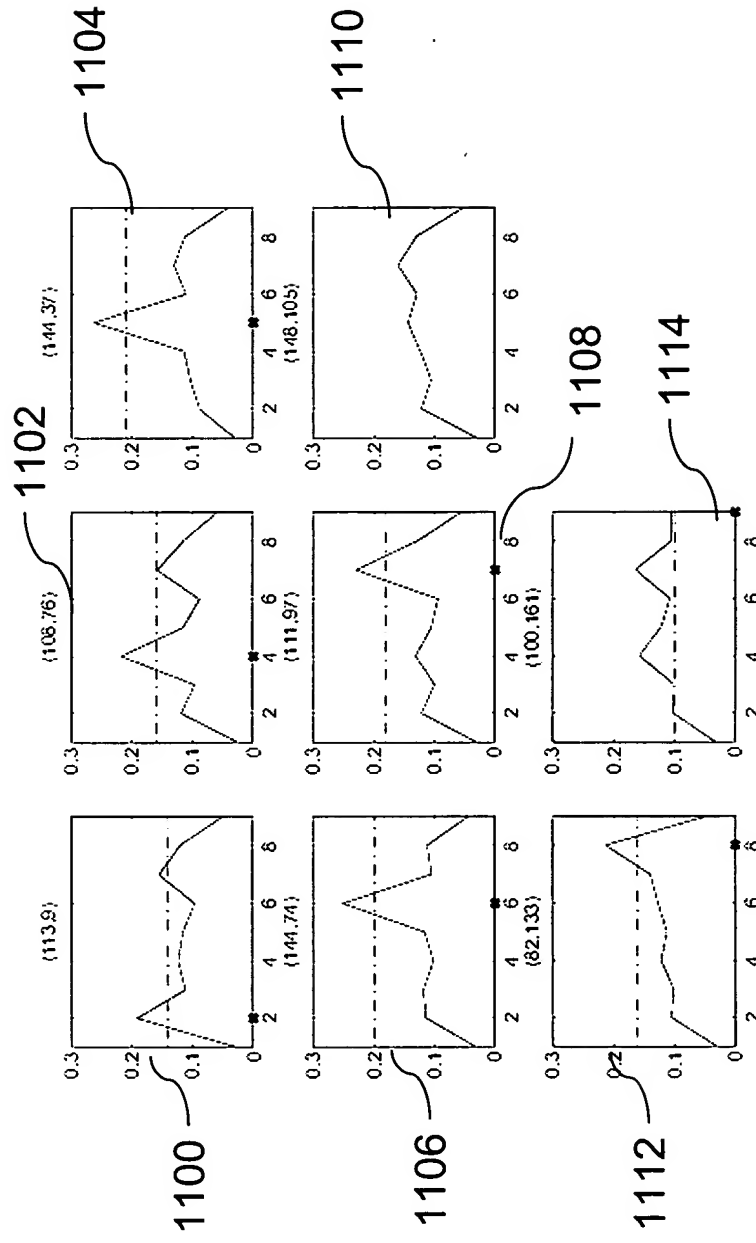
The prior information (i.e., the shape representation averaged over a large number of viewing angles), which was computed before applying the embodiment of the invention.

FIG. 9



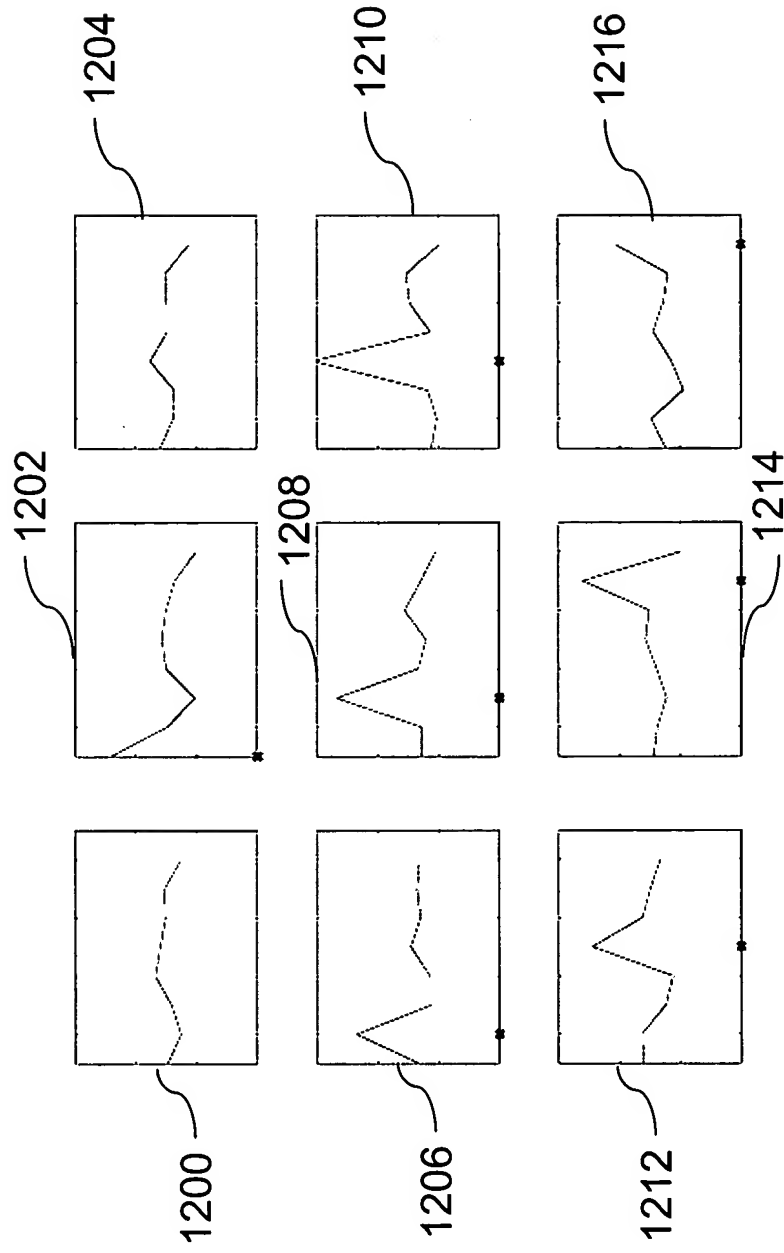
The posterior probability matrix $P(X,Y)$ prior to the Sinkhorn normalization procedure.

FIG. 10



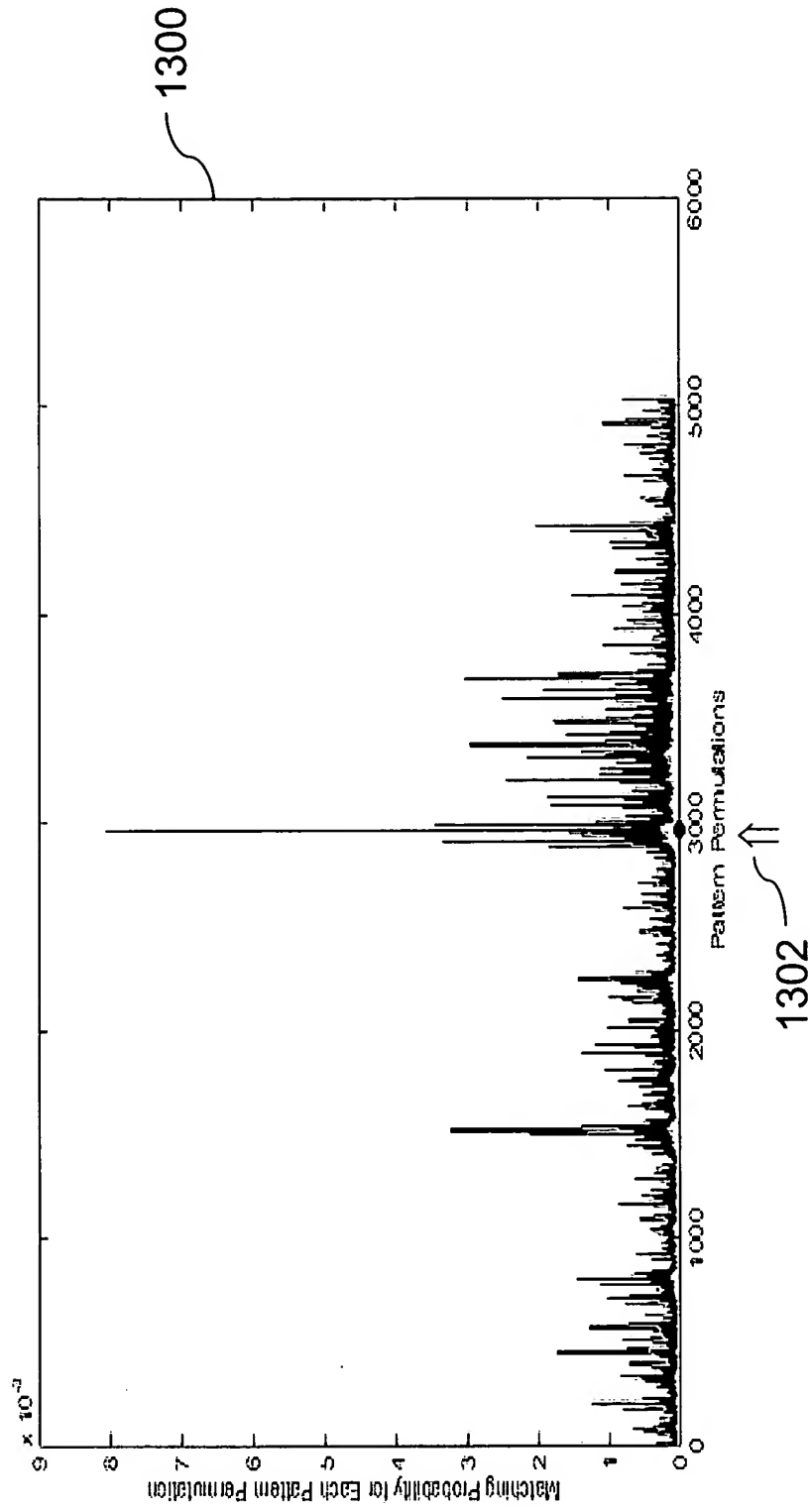
The a posteriori probabilities for each of the features in the front image, obtained from each of the rows of the correspondence matrix.

FIG. 11



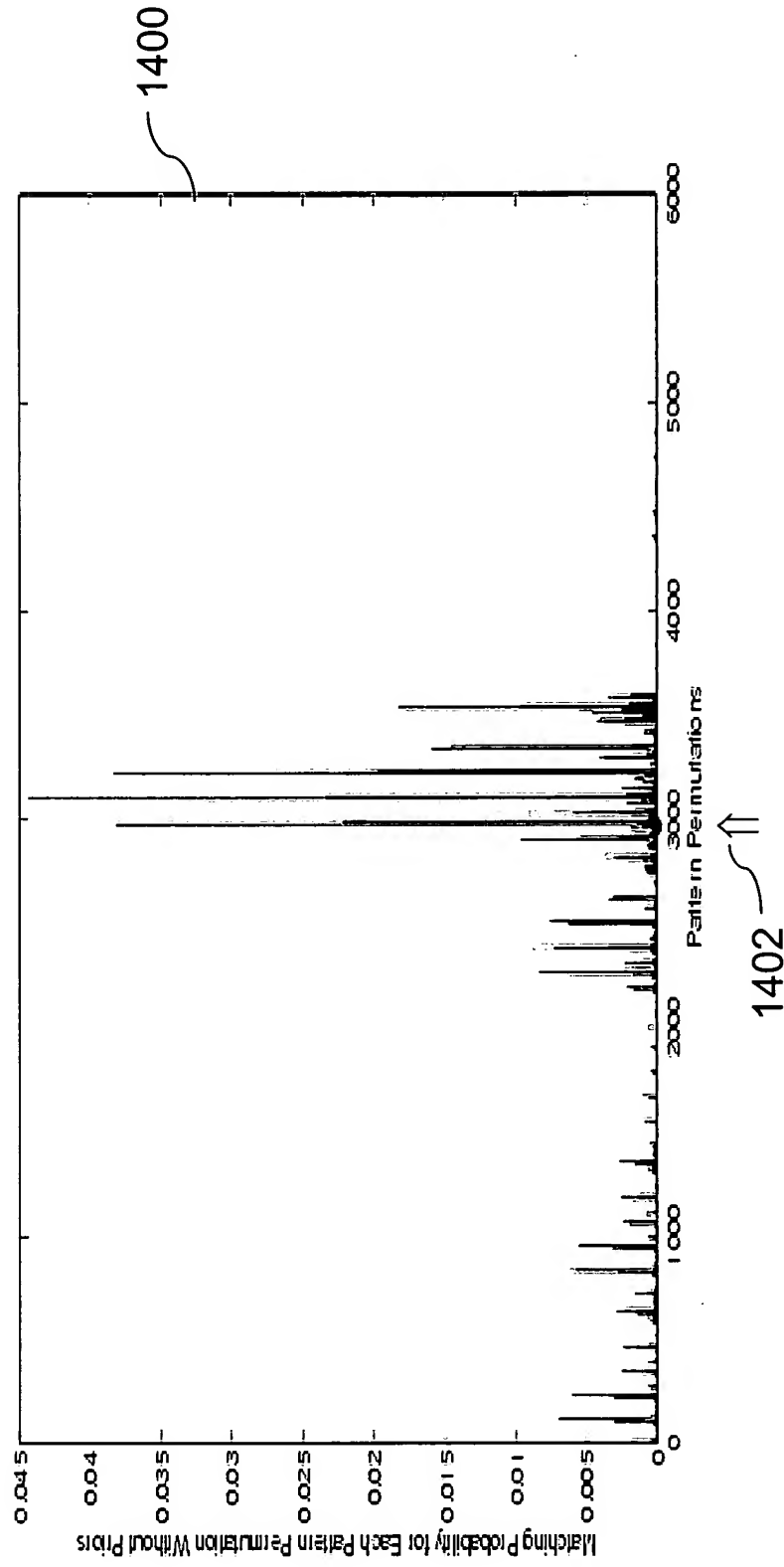
The a posteriori probabilities for each of the features in the front image, obtained from each of the columns of the correspondence matrix.

FIG. 12



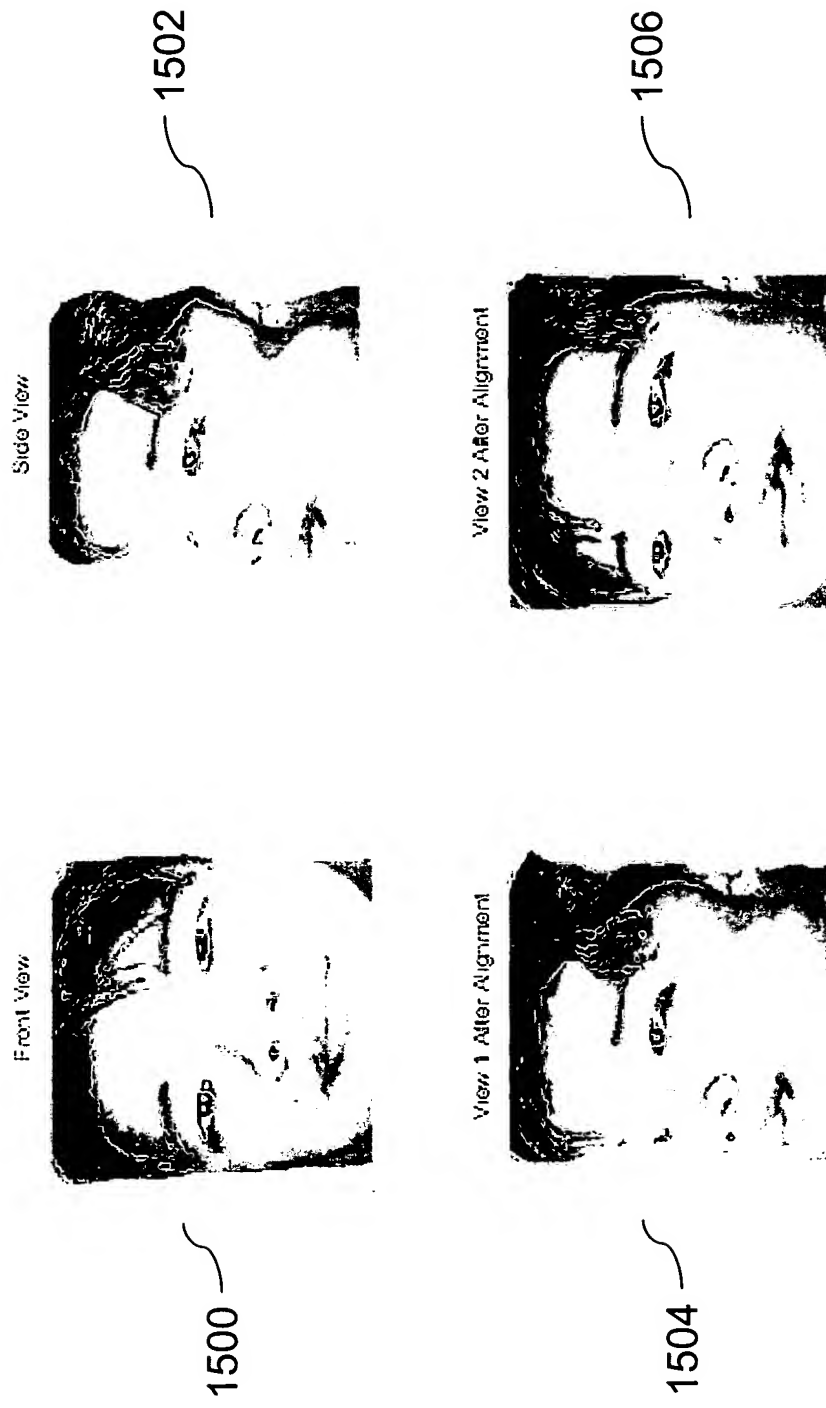
The probability of matching X against all permutations of Y. The true value is marked with 1302, an arrow below the horizontal axis.

FIG. 13



The probability of match for the shape of each feature in the front image against all possible combinations of the features in the side view, for the case where prior information is not available. The true value is marked with 1402, an arrow below the horizontal axis.

FIG. 14



1500 and 1502 are the 3D models used as input to the algorithm.
1504 and 1506 are the 3D models obtained after the alignment.

FIG. 15